speeds and torques at a frequency of at least 5 Hz for transient cycles and at least 1 Hz for steady-state cycles. For transient cycles, you may record the feedback speeds and torques at lower frequencies (as low as 1 Hz) if you record the average value over the time interval between recorded values. Calculate the average values based on feedback values updated at a frequency of at least 5 Hz. Use these recorded values to calculate cycle-validation statistics and total work.

(d) For constant-speed engines, operate the engine with the same production governor you used to map the engine in §1065.510 or simulate the in-use operation of a governor the same way you simulated it to map the engine in §1065.510. Command reference torque values sequentially to perform a duty cycle. Issue torque commands at a frequency of at least 5 Hz for transient cycles and at least 1 Hz for steady-state cycles (*i.e.*, discrete-mode, ramped-modal). Linearly interpolate between the 1 Hz reference values specified in the standard-setting part to determine more frequently issued reference torque values. During an emission test, record the feedback speeds and torques at a frequency of at least 5 Hz for transient cycles and at least 1 Hz for steady-state cycles. For transient cycles, you may record the feedback speeds and torques at lower frequencies (as low as 1 Hz) if you record the average value over the time interval between recorded values. Calculate the average values based on feedback values updated at a frequency of at least 5 Hz. Use these recorded values to calculate cycle-validation statistics and total work.

(e) You may perform practice duty cycles with the test engine to optimize operator demand and dynamometer controls to meet the cycle-validation criteria specified in §1065.514.

[73 FR 37317, June 30, 2008, as amended at 79 FR 23774, Apr. 28, 2014]

§ 1065.514 Cycle-validation criteria for operation over specified duty cycles.

Validate the execution of your duty cycle according to this section unless the standard-setting part specifies otherwise. This section describes how to determine if the engine's operation during the test adequately matched the reference duty cycle. This section applies only to speed, torque, and power from the engine's primary output shaft. Other work inputs and outputs are not subject to cycle-validation criteria. You must compare the original reference duty cycle points generated as described in §1065.512 to the corresponding feedback values recorded during the test. You may compare reference duty cycle points recorded during the test to the corresponding feedback values recorded during the test as long as the recorded reference values match the original points generated in §1065.512. The number of points in the validation regression are based on the number of points in the original reference duty cycle generated in §1065.512. For example if the original cycle has 1199 reference points at 1 Hz, then the regression will have up to 1199 pairs of reference and feedback values at the corresponding moments in the test. The feedback speed and torque signals may be filtered—either in real-time while the test is run or afterward in the analysis program. Any filtering that is used on the feedback signals used for cycle validation must also be used for calculating work. Feedback signals for control loops may use different filtering.

(a) *Testing performed by EPA.* Our tests must meet the specifications of paragraph (f) of this section, unless we determine that failing to meet the specifications is related to engine performance rather than to shortcomings of the dynamometer or other laboratory equipment.

(b) *Testing performed by manufacturers.* Emission tests that meet the specifications of paragraph (f) of this section satisfy the standard-setting part's requirements for duty cycles. You may ask to use a dynamometer or other laboratory equipment that cannot meet those specifications. We will approve your request as long as using the alternate equipment does not adversely affect your ability to show compliance with the applicable emission standards.

(c) *Time-alignment.* Because time lag between feedback values and the reference values may bias cycle-validation results, you may advance or delay the entire sequence of feedback engine speed and torque pairs to synchronize them with the reference sequence. If you advance or delay feedback signals for cycle validation, you must make the same adjustment for calculating work. You may use linear interpolation between successive recorded feedback signals to time shift an amount that is a fraction of the recording period.

(d) *Omitting additional points.* Besides engine cranking, you may omit additional points from cycle-validation statistics as described in the following table:

TABLE 1 OF § 1065.514—PERMISSIBLE CRITERIA FOR OMITTING POINTS FROM DUTY-CYCLE REGRESSION STATISTICS

When operator demand is at its . . .	you may omit . . .	if . . .
For reference duty cycles that are specified in terms of speed and torque (f_{nref}, T_{ref})		
minimum	power and torque	T_{ref} <0% (motoring).
minimum	power and speed	f_{nref} = 0% (idle speed) and T_{ref} = 0% (idle torque) and $T_{ref} - (2\% \cdot T_{max\ mapped}) < T < T_{ref} + (2\% \cdot T_{max\ mapped})$.
minimum	power and either torque or speed.	$f_n > f_{nref}$ or $T > T_{ref}$ but not if $f_n > (f_{nref} \cdot 102\%)$ and $T > T_{ref} \pm (2\% \cdot T_{max\ mapped})$.
maximum	power and either torque or speed.	$f_n < f_{nref}$ or $T < T_{ref}$ but not if $f_n < (f_{nref} \cdot 98\%)$ and $T < T_{ref} - (2\% \cdot T_{max\ mapped})$.
For reference duty cycles that are specified in terms of speed and power (f_{nref}, P_{ref})		
minimum	power and torque	P_{ref} <0% (motoring).
minimum	power and speed	f_{nref} = 0% (idle speed) and P_{ref} = 0% (idle power) and $P_{ref} - (2\% \cdot P_{max\ mapped}) < P < P_{ref} + (2\% \cdot P_{max\ mapped})$.
minimum	power and either torque or speed.	$f_n > f_{nref}$ or $P > P_{ref}$ but not if $f_n > (f_{nref} \cdot 102\%)$ and $P > P_{ref} + (2\% \cdot P_{max\ mapped})$.
maximum	power and either torque or speed.	$f_n < f_{nref}$ or $P < P_{ref}$ but not if $f_n < (f_{nref} \cdot 98\%)$ and $P < P_{ref} - (2\% \cdot P_{max\ mapped})$.

(e) *Statistical parameters.* Use the remaining points to calculate regression statistics described in § 1065.602. Round calculated regression statistics to the same number of significant digits as the criteria to which they are compared. Refer to Table 2 of § 1065.514 for the default criteria and refer to the standard-setting part to determine if there are other criteria for your engine. Calculate the following regression statistics:

(1) Slopes for feedback speed, a_{1fn}, feedback torque, a_{1T}, and feedback power a_{1P}.

(2) Intercepts for feedback speed, a_{0fn}, feedback torque, a_{0T}, and feedback power a_{0P}.

(3) Standard estimates of error for feedback speed, SEE_{fn}, feedback torque, SEE_T, and feedback power SEE_P.

(4) Coefficients of determination for feedback speed, r^2_{fn}, feedback torque, r^2_T, and feedback power r^2_P.

(f) *Cycle-validation criteria.* Unless the standard-setting part specifies otherwise, use the following criteria to validate a duty cycle:

(1) For variable-speed engines, apply all the statistical criteria in Table 2 of this section.

(2) For constant-speed engines, apply only the statistical criteria for torque in Table 2 of this section.

(3) For discrete-mode steady-state testing, apply cycle-validation criteria by treating the sampling periods from the series of test modes as a continuous sampling period, analogous to ramped-modal testing and apply statistical criteria as described in paragraph (f)(1) or (f)(2) of this section. Note that if the gaseous and particulate test intervals are different periods of time, separate validations are required for the gaseous and particulate test intervals. Table 2 follows:

TABLE 2 OF § 1065.514—DEFAULT STATISTICAL CRITERIA FOR VALIDATING DUTY CYCLES

Parameter	Speed	Torque	Power
Slope, a_1	$0.950 \leq a_1 \leq 1.030$	$0.830 \leq a_1 \leq 1.030$	$0.830 \leq a_1 \leq 1.030$.

TABLE 2 OF § 1065.514—DEFAULT STATISTICAL CRITERIA FOR VALIDATING DUTY CYCLES—Continued

Parameter	Speed	Torque	Power
Absolute value of intercept, $\lvert a_0 \rvert$	≤10% of warm idle	≤2% of maximum mapped torque.	≤2% of maximum mapped power.
Standard error of estimate, *SEE*.	≤5% of maximum test speed	≤10% of maximum mapped torque.	≤10% of maximum mapped power.
Coefficient of determination, r^2	≥0.970	≥0.850	≥0.910.

[73 FR 37318, June 30, 2008, as amended at 73 FR 59330, Oct. 8, 2008; 75 FR 23042, Apr. 30, 2010; 76 FR 57450, Sept. 15, 2011]

§ 1065.516 Sample system decontamination and preconditioning.

This section describes how to manage the impact of sampling system contamination on emission measurements. Use good engineering judgment to determine if you should decontaminate and precondition your sampling system. Contamination occurs when a regulated pollutant accumulates in the sample system in a high enough concentration to cause release during emission tests. Hydrocarbons and PM are generally the only regulated pollutants that contaminate sample systems. Note that although this section focuses on avoiding excessive contamination of sampling systems, you must also use good engineering judgment to avoid loss of sample to a sampling system that is too clean. The goal of decontamination is not to perfectly clean the sampling system, but rather to achieve equilibrium between the sampling system and the exhaust so emission components are neither lost to nor entrained from the sampling system.

(a) You may perform contamination checks as follows to determine if decontamination is needed:

(1) For dilute exhaust sampling systems, measure hydrocarbon and PM emissions by sampling with the CVS dilution air turned on, without an engine connected to it.

(2) For raw analyzers and systems that collect PM samples from raw exhaust, measure hydrocarbon and PM emissions by sampling purified air or nitrogen.

(3) When calculating zero emission levels, apply all applicable corrections, including initial THC contamination and diluted (CVS) exhaust background corrections.

(4) Sampling systems are considered contaminated if either of the following conditions applies:

(i) The hydrocarbon emission level exceeds 2% of the flow-weighted mean concentration expected at the HC standard.

(ii) The PM emission level exceeds 5% of the level expected at the standard and exceeds 20 μg on a 47 mm PTFE membrane filter.

(b) To precondition or decontaminate sampling systems, use the following recommended procedure or select a different procedure using good engineering judgment:

(1) Start the engine and use good engineering judgment to operate it at a condition that generates high exhaust temperatures at the sample probe inlet.

(2) Operate any dilution systems at their expected flow rates. Prevent aqueous condensation in the dilution systems.

(3) Operate any PM sampling systems at their expected flow rates.

(4) Sample PM for at least 10 min using any sample media. You may change sample media at any time during this process and you may discard them without weighing them.

(5) You may purge any gaseous sampling systems that do not require decontamination during this procedure.

(6) You may conduct calibrations or verifications on any idle equipment or analyzers during this procedure.

(c) If your sampling system is still contaminated following the procedures specified in paragraph (b) of this section, you may use more aggressive procedures to decontaminate the sampling system, as long as the decontamination does not cause the sampling system to